Amendments to the Specification:

Please replace paragraph [0016] with the following amended paragraph:

[0016]The invention will also encounter conditions that will require it to determine the liquid levels on more than one tank at a time. This task is accomplished by attaching more sensors to the appropriate ports on the smart transceiver board of the invention. The invention has been designed to monitor the liquid levels of one or more tanks at a time. The invention determines the liquid level of tanks using the current float technologies in the tanks by means of a specially developed sensor cap as shown in Fig. 2. This cap fits externally on the stem of the float device in the tank. This cap contains a follower magnet assembly **34** which travels up and down and magnetically **28** follows the magnet **25** in the tank's own float. This vertical movement is a constantly occurring cyclical process that happens as the tank is filled and emptied. The follower magnet assembly **34** rides on a spiral shaft **36** that is positioned parallel to the float stem **26** on the tank. An optional linear programmable Hall effect sensor **24** that induces a voltage signal in ratiometric proportion to the proximate magnetic field created by the magnet **25** traveling in a casing **27**. As the magnetic flux density at the sensor **24** changes proportional to its proximity of the magnet **25**, or as the strength of the magnetic field changes, driven by the upward and downward movement of the magnet **25** on the float stem **26** that follows tank level changes, even as small as 1 gauss, the sensor **24** registers a change in voltage. The sensor **24** is optionally programmed on a smart transceiver board **23** to a specified sensitivity that calibrates to a certain number of millivolts per gauss. The set quiescence voltage is approximately 0.5 volts. As the magnet **25** moves, voltage is added to the quiescence voltage from the sensitivity calculation performed during sensor calibration. By reading the voltage, and looking up its value in a programmed table, the liquid level inside the tank is determined and compared with the reading from the low torque potentiometer **32** connected to shaft **36**. The shaft **36** has a spiraling track fitted with a jeweled bearing assembly (not shown) on the lower end. The follower magnet assembly **34** has a corresponding and matching track that causes the shaft **36** to spin in the bearing

as the follower magnet assembly **34** rises and falls. The position of the follower magnet assembly **34** on the spinning shaft is determined and reported by a low torque potentiometer **32** (which is connected to the upper end of the shaft) to the smart transceiver board **23**. The controlling software can then determine the amount of liquid in the tank by the information it receives from the potentiometer **32** connected to the spinning shaft **36**. The spiraled shaft **36**, the follower magnet assembly **34** and sensor housing **22** have been specifically designed for this application. The rotational requirements for the most accurate readability of the device were calculated and matched with the low torque potentiometer **32** to achieve optimum functionality. The smart transceiver **23**, hall effect sensor **24**, and potentiometer **32** are enclosed in a water resistant housing **22**.